3. The robot of claim 1, wherein the edge detection element comprises:

a first switch that closes when a front end wheel travels the predetermined distance downward; and

a second switch that closes when a rear end wheel travels the predetermined distance downward.

4. The robot of claim ~~4~~ 3, wherein each of the first switch and the second switch comprise a leaf switch.

5. The robot of claim 4, wherein the closing of the first switch completes a first circuit causing a signal to be sent to the robot indicating that an edge was detected near the front end wheel.

6. The robot of claim 5, wherein the closing of the second switch completes a second circuit causing a signal to be sent to the robot indicating that an edge was detected near the rear end wheel.

7. The robot of claim 3, wherein:

closure of the first switch causes the driving mechanism to move the robot